

REPLACEMENT CLAIMS

A1 5. (Amended) Method according to claim 1, characterized in that the transfer of the gripping mechanism is programmed in by means of a so called "teach-in" process, wherein a work cycle is programmed in by an operator by actual transfer of the gripping mechanism (12) through the work cycle, and successive registration of desired values is programmed in with respect to the rotor units forming part of the said motors (26,27), so that the control computer (51), through communication with a registration unit (52), can subsequently ensure automatic operation.

A2 15. (Amended) Robot unit according to claim 1, characterized by a further drive belt (36), which is drivably connected to a transmission (39) on the lower end (22A) of the vertical beam (22), in order to be able to perform further motion with the gripping mechanism (12).
